

**THE INVENTION CLAIMED IS:**

1. A method of mobile device control comprising:  
moving a surrogate under wireless control by a user; and  
autonomously moving the surrogate to regain wireless control when the wireless  
control is lost.
2. The method as claimed in claim 1 additionally comprising:  
autonomously moving the surrogate along a previously determined route.
3. The method as claimed in claim 1 wherein:  
autonomously moving the surrogate to regain wireless control occurs after a period of  
time.
4. The method as claimed in claim 1 wherein:  
autonomously moving the surrogate includes measuring distance and avoiding  
collisions by the surrogate.
5. The method as claimed in claim 1 wherein:  
moving the surrogate under wireless control includes logging forward motion using  
at least one of dead reckoning, odometry, directional measurement, differential  
wheel rotation, and a combination thereof.
6. The method as claimed in claim 1 wherein:  
autonomously moving the surrogate uses logged information of forward movement  
using at least one of dead reckoning, odometry, directional measurement,  
differential wheel rotation, and a combination thereof; and  
autonomously moving the surrogate uses waypoints back along a forward movement  
path for backtracking movement.
7. A method of mobile telepresencing comprising:  
moving a surrogate under real-time wireless control by a user; and  
autonomously moving the surrogate to an area with adequate wireless coverage to  
regain wireless control when the wireless control is lost for a period of time.
8. The method as claimed in claim 7 additionally comprising:  
autonomously moving the surrogate along at least one of a previously determined  
route, a distance, a destination, a direction, or a combination thereof.

9. The method as claimed in claim 7 wherein:  
losing wireless control includes degradation of the control to a threshold level;  
autonomously moving the surrogate to regain wireless control occurs after a period of  
time.

5 10. The method as claimed in claim 7 wherein:  
autonomously moving the surrogate includes;  
backtracking while measuring distance and avoiding collisions by the  
surrogate;  
stopping the surrogate for an obstacle; and  
10 resuming backtracking after removal of the obstacle.

11. The method as claimed in claim 7 wherein:  
moving the surrogate under wireless control includes logging forward motion using  
at least one of dead reckoning, odometry, directional measurement, differential  
wheel rotation, and a combination thereof.

15 12. The method as claimed in claim 7 wherein:  
autonomously moving the surrogate to backtrack uses logged information of forward  
movement using at least one of dead reckoning, odometry, directional  
measurement, differential wheel rotation, and a combination thereof;  
autonomously moving the surrogate to backtrack uses a slower speed than forward  
20 speed; and  
autonomously moving the surrogate uses waypoints back along a forward movement  
path for backtracking movement considering the slower speed of backtracking.

13. A mobile device control system comprising:  
a surrogate movable under wireless control by a user; and  
25 a computer/transceiver system on the surrogate for moving the surrogate to regain  
wireless control when the wireless control is lost.

14. The system as claimed in claim 13 wherein:  
the computer/transceiver system for autonomously moving the surrogate along a  
previously determined route.

30 15. The system as claimed in claim 13 wherein:  
the computer/transceiver system for autonomously moving the surrogate to regain  
wireless control occurs after a period of time.

16. The system as claimed in claim 13 wherein:  
the computer/transceiver system for autonomously moving the surrogate includes  
measuring distance and avoiding collisions by the surrogate.

17. The system as claimed in claim 13 wherein:  
the computer/transceiver system includes logging forward motion using at least one  
of dead reckoning, odometry, directional measurement, differential wheel  
rotation, and a combination thereof.

18. The system as claimed in claim 13 wherein:  
the computer/transceiver system uses logged information of forward movement using  
at least one of dead reckoning, odometry, directional measurement, differential  
wheel rotation, and a combination thereof; and  
the computer/transceiver system calculates waypoints back along a forward  
movement path for backtracking movement.

19. A mobile telepresencing comprising:  
a surrogate movable under real-time wireless control by a user; and  
a computer/transceiver system for autonomously moving the surrogate to an area with  
adequate wireless coverage to regain wireless control when the wireless  
control is lost for a period of time.

20. The system as claimed in claim 19 additionally comprising:  
the computer/transceiver system for autonomously moving the surrogate along at least  
one of a previously determined route, a distance, a destination, a direction, or a  
combination thereof.

21. The system as claimed in claim 19 wherein:  
the computer/transceiver system for determining degradation of the wireless control to  
a threshold level;  
the computer/transceiver system for autonomously moving the surrogate to regain  
wireless control occurs after a period of time.

22. The system as claimed in claim 19 wherein:

the computer/transceiver system for autonomously moving the surrogate includes;

backtracking means for measuring distance and avoiding collisions by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for resuming backtracking after removal of the obstacle.

23. The system as claimed in claim 19 wherein:

the computer/transceiver system includes means for logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

24. The system as claimed in claim 19 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof for backtracking;

the computer/transceiver system provides a slower speed than forward speed for backtracking by the surrogate; and

the computer/transceiver system uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.